

Fenrir Flight 24:

Video can be found here:

- Front van cam: <https://www.flickr.com/photos/100936386@N02/18598815496/in/dateposted-public/>
- Rear van cam: <https://www.flickr.com/photos/100936386@N02/18002197054/in/dateposted-public/>

The goal for this flight was to put doublets on theta and then phi commands to test attitude tracking. An auto throttle was running with a set point of 23 m/s during the doublets. The pilot got too slow following launch and took a while to get to the test condition, so we only get a few seconds of data. Gains for this flight were:

- static double roll_gain[3] = {0.15,0.50,0}; // PI gains for roll tracker and roll damper
- static double pitch_gain[3] = {-0.3,-0.50,0}; // PI gains for theta tracker and pitch damper
- static double v_gain[2] = {0.091, 0.020}; // PI gains for speed tracker